Amendment to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1. (Original) A method for determining a float angle of a motor vehicle, comprising:

determining a yaw rate of the motor vehicle by a yaw rate sensor;

determining a direction of a velocity in the center of gravity of the motor vehicle by performing a frequency analysis of a signal received by a GPS receiver located in the motor vehicle; and

determining the float angle as a function of at least the yaw rate and the direction of the velocity of the motor vehicle.

2. (Currently Amended) [[The]] method ~~as recited in Claim 1~~ for determining a float angle of a motor vehicle, ~~further~~ comprising:

determining a yaw rate of the motor vehicle by a yaw rate sensor;

determining a direction of a velocity in the center of gravity of the motor vehicle by performing a frequency analysis of a signal received by a GPS receiver located in the motor vehicle;

determining the float angle as a function of at least the yaw rate and the direction of the velocity of the motor vehicle;

determining an angular speed from the direction of the velocity; and

performing the determining of the float angle on the basis of the angular speed .

3. (Original) The method as recited in Claim 2, wherein:

the angular speed corresponds to a rotational speed of a vector that corresponds to the velocity.

4. (Original) The method as recited in Claim 3, further comprising:

determining a difference between the yaw rate and the angular speed; and

performing the determining of the float angle on the basis of the difference by integration over time.

5. (Currently Amended) [[The]] A method ~~as recited in Claim 1~~ for determining a float angle of a motor vehicle, comprising:

determining a yaw rate of the motor vehicle by a yaw rate sensor;

determining a direction of a velocity in the center of gravity of the motor vehicle by performing a frequency analysis of a signal received by a GPS receiver located in the motor vehicle; and determining the float angle as a function of at least the yaw rate and the direction of the velocity of the motor vehicle, wherein:

the determining of the direction of the velocity is performed based on the Doppler effect.

6. (Original) A device for determining the float angle of a motor vehicle, comprising:

a yaw rate sensor for determining a yaw rate of the motor vehicle;

a GPS receiver located in the motor vehicle and for determining a direction of a velocity in the center of gravity of the motor vehicle by analyzing a frequency of a received signal; and

a detection arrangement for determining the float angle on the basis of at least the yaw rate and the direction of the velocity of the motor vehicle.

7. (Currently Amended) [[The]] A device ~~as recited in Claim 6~~ for determining the float angle of a motor vehicle, comprising:

a yaw rate sensor for determining a yaw rate of the motor vehicle;

a GPS receiver located in the motor vehicle and for determining a direction of a velocity in the center of gravity of the motor vehicle by analyzing a frequency of a received signal; and

a detection arrangement for determining the float angle on the basis of at least the yaw rate and the direction of the velocity of the motor vehicle, wherein:

an angular speed is determined in the detection arrangement from the velocity; and

the float angle is determined on the basis of the angular speed.

8. (Original) The device as recited in Claim 7, wherein:

the angular speed corresponds to a rotational speed of a vector that corresponds to the velocity.

9. (Original) The device as recited in Claim 8, wherein:

the detection arrangement determines a difference between the yaw rate and the angular speed; and

the detection arrangement determines the float angle on the basis of the difference by integration over time.